

**IN THE CLAIMS:**

The text of all pending claims, (including withdrawn claims) is set forth below. Cancelled and not entered claims are indicated with claim number and status only. The claims as listed below show added text with underlining and deleted text with ~~strikethrough~~. The status of each claim is indicated with one of (original), (currently amended), (cancelled), (withdrawn), (new), (previously presented), or (not entered).

Please ADD new claims 17-18 in accordance with the following:

1. (Original) A robot system comprising:  
a changeable robot mechanism section;  
a robot control section for controlling respective axes of said robot mechanism section;  
and  
a memory provided at said robot mechanism section, and storing information concerning parameters inherent to individuality of said robot mechanism section to be used in calculation for a locus control of the robot mechanism section by said robot control section, said memory being connected with said robot control section so that the stored information is read by said robot control section.
2. (Original) A robot system according to claim 1, wherein said stored information further includes information designating an algorithm to be used in calculation for the locus control by said control section.
3. (Original) A robot system according to claim 1, wherein said stored information includes data of a measured or estimated value of a length of a predetermined part of said mechanism section.
4. (Original) A robot system according to claim 1, wherein said stored information includes data of an error between a measured or estimated value and a design value of a length of a predetermined part of said mechanism section.
5. (Original) A robot system according to claim 1, wherein said robot mechanism section has motors for driving the respective axes and one or more encoders for detecting rotational positions of the motors, said memory comprises a nonvolatile memory associated with one of said encoders, and said robot control section reads information stored in the nonvolatile

memory using a communication line between said one of the encoders and said robot control section.

6. (Original) A robot system according to claim 1, wherein said memory stores identification information for identifying individuality of the robot mechanism section, and said robot control section reads the identification information from said memory and if the read identification information is different from corresponding identification information stored in the robot control section, the read information including the identification information is substituted for the corresponding information stored in the robot control section.

7. (Original) A robot system according to claim 1, wherein said stored information is automatically read by the robot control section when a power supply to said robot control section is turned on.

8. (Original) A robot system according to claim 1, wherein said stored information is read by said robot control section in response to a manual operation on said robot control section by an operator.

9. (Original) A robot system comprising:  
a robot mechanism section including a changeable mechanical unit;  
a robot control section for controlling respective axes of said robot mechanism section;  
and  
a memory provided at said mechanical unit and storing information concerning parameters inherent to individuality of said mechanical unit to be used in calculation for a locus control of the robot mechanism section by said robot control section, said memory being connected with said robot control section so that the stored information is read by said robot control section.

10. (Original) A robot system according to claim 9, wherein said stored information further includes information designating an algorithm to be used in calculation for the locus control by said robot control section.

11. (Original) A robot system according to claim 9, wherein said stored information includes data of a measured or estimated value of a length of a predetermined part of said

mechanical unit.

12. (Original) A robot system according to claim 9, wherein said stored information includes data of an error between a measured or estimated value and a design value of a length of a predetermined part of said robot mechanical unit.

13. (Original) A robot system according to claim 9, wherein said mechanical unit has one or more motors for driving one or more axes, and one or more encoders for detecting rotation of the motors, said memory comprises a nonvolatile memory associated with one of said encoders, and said robot control section reads information stored in the nonvolatile memory using a communication line between said one of the encoders and said robot control section.

14. (Original) A robot system according to claim 9, wherein said memory stores identification information for identifying individuality of the mechanical unit, and said robot control section reads the identification information from said memory and if the read identification information is different from corresponding identification information stored in the robot control section, the read information including the identification information is substituted for the corresponding information stored in the robot control section.

15. (Original) A robot system according to claim 1, wherein said stored information is automatically read by the robot control section when a power supply to said robot control section is turned on.

16. (Original) A robot system according to claim 9, wherein said stored information is read by said robot control section in response to a manual operation on said robot control section by an operator.

17. (New) A robot system, comprising:  
a changeable robot mechanism section having a wrist unit detachable from a main unit, the wrist unit having at least one memory storing information concerning parameters inherent to individuality of the wrist unit, the main unit having at least one memory storing information concerning parameters inherent to individuality of the main unit; and  
a robot control section for controlling the robot mechanism section connected to the robot mechanism section;

wherein the robot control section reads the stored information from the main unit and the stored information from the wrist unit to calculate a locus control of the robot mechanism section.

18. (New) A method for calculating a locus of a robot having a changeable robot mechanism section in communication with a robot control section, comprising:

reading information concerning parameters inherent to individuality of the robot mechanism section stored in memories at the robot mechanism section;

comparing the stored information with corresponding data stored in a memory of the robot control section to determine whether a kind of robot is changed and to determine whether at least one of the mechanical units of the robot mechanism section has changed;

rewriting data indicating the kind of robot in the memory of the robot control section, if it is determined that the kind of robot has changed, and rewriting data indicating the changed mechanical unit, if it is determined that one of the mechanical units has changed; and

computing the locus of the robot using the parameters inherent to individuality of the robot mechanism section.